

Abstract of the Disclosure

Provided is a hand/eye calibration method by using a projective invariant shape descriptor of a two-dimensional image. The method includes calculating a projective invariant shape descriptor of a two-dimensional image from at least two images obtained by a camera mounted on a robot hand, at a predetermined time interval, extracting corresponding points between the images by using the projective invariant shape descriptor, calculating a rotation matrix for the corresponding points from translation of the robot hand, calculating translation vector for the corresponding points from translation and rotation of the robot hand, and finding a relation between the robot hand and the camera based on the rotation matrix and the translation vector.